

In the Claims:

Please amend the claims as follows:

1. (cancelled)
2. (cancelled)
3. (new) A system for selection and transport of objects out of a flow of a plurality of objects in an operation area, the system comprising:
 - a system for detecting objects from the flow of the plurality of objects present in the operation area;
 - an operating system comprising a computer memory for storing information on the objects present in the operation area, means for defining a transport direction of each object in the operation area, and means for defining a plurality of passageways along the transport direction of each object; and
 - an industrial robot comprising a manipulator operative to extract an object from the flow of the plurality of objects and move the extracted object in the transport direction.
4. (new) The system according to claim 3, wherein the operating system further comprises means for calculating the presence of other objects penetrating into each of said passageways.

5. (new) The system according to claim 3, further comprising:
a transport system for continuous flow of the objects.
6. (new) The system according to claim 3, wherein the transport system transports the products in a horizontal direction.
7. (new) The system according to claim 3, wherein the transport system comprises a conveyor belt.
8. (new) The system according to claim 3, wherein the operating system further comprises means for selecting a certain type of object from among the plurality of objects.
9. (new) The system according to claim 3, wherein the passageways comprise tunnels.
10. (new) The system according to claim 3, wherein the system for detecting objects comprises a vision system.
11. (new) A method of selecting an object out of a plurality of objects in an operation area for transport to a predetermined location, the method comprising:
detecting the plurality of moving objects present in the operation area;
storing object and location information in a computer memory; and
selecting an object to be picked from the plurality of objects, wherein selecting the object comprises

defining a transport direction for each of the plurality of objects present in the operation area,
defining a passageway along the transport direction of each of said plurality of objects,
calculating for each passageway the presence of penetration of any other of said plurality objects, and
selecting an object from said plurality of objects for which a passageway is free from penetration.

12. (new) The method according to claim 11, further comprising:

picking the object; and

moving the object along the selected passageway.

13. (new) The method according to claim 12, wherein the object is picked without disturbing other objects in the operation area.

14. (new) The method according to claim 11, wherein the objects are moved horizontally.

15. (new) The method according to claim 14, wherein the objects are moved in a circular direction.

16. (new) The method according to claim 11, wherein the objects are moved vertically.

17. (new) The method according to claim 11, further comprising:
determining information regarding the objects, the information comprising size, position, speed, or orientation.

18. (new) The method according to claim 12, wherein the object is picked without disturbing other objects in the operation area.

19. (new) The method according to claim 11, wherein selecting the object further comprises
selecting an optimal object based upon speed of the objects.

20. (new) The method according to claim 11, further comprising:
repeatedly moving the objects through the operation area.